

## **AMENDMENTS TO SPECIFICATION**

**Amend the paragraph added via Preliminary Amendment to page 1, line 1 before the first paragraph as follows:**

### **CROSS REFERENCE TO RELATED APPLICATIONS**

~~This application claims the benefit of~~ is filed under 35 U.S.C. 371 as a national stage entry of PCT/IB 04/002020, filed June 17, 2004, which claims the benefit of U.S. provisional application serial no. 60/479,576 filed June 8, 2003 and U.S. provisional application serial no. 60/512,491 filed October 18, 2003, both each of which are ~~is~~ incorporated herein by reference.

**Amend the paragraph beginning at page 7, line 24 and extending to page 8, line 7, of the filed application as follows:**

With reference to FIGS. 2-4B, and continuing reference to FIGURE 1, in a preferred embodiment, the image-guided interventional medical procedure system 10 also includes a robotic arm 190 preferably carried on the stationary gantry 110. The robotic arm 190 supports a remotely held needle guide apparatus 200 carrying an interventional implement or other like medical device 191 e.g., an ablation probe or a biopsy needle 192 at a desired location and trajectory. The medical device 191 is supported within the examination region 112 as shown. The robotic arm 190 is preferably a fully adjustable multi-jointed multi-segmented arm with each joint having at least one degree of freedom. As will be described in greater detail later herein, a medical device 191, preferably the ablation probe or biopsy needle 192, is held by the needle guide apparatus 200 (as best seen in FIGURE 3). Accordingly, by appropriately arranging the robotic arm 190 (i.e., flexing or otherwise adjusting the multiple joints and/or segments, but preferably by executing a program which aligns the arm to the planned trajectory) and by appropriately positioning the subject 20 and the robotic arm 190 relative to one another, any arbitrary position and/or orientation of the biopsy needle 192 relative to the subject 20 is achieved as desired. Preferably, the position and/or orientation of the medical device 191 defines a physical path coincident with the virtual planned trajectory.